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READOUT CONTROLLING APPARATUS, REPRODUCING APPARATUS,
RECORDING APPARATUS, AND READOUT CONTROLLING METHOD

5 BACKGROUND OF THE INVENTION

1. Field of the Invention

The present invention relates to a readout
controlling apparatus, player, and recorder of a
digital disk or other recording media and a readout
10 controlling method.

2. Description of the Related Art

When playing back a digital versatile disk
(DVD), a DVD player etc. converts an analog signal
read from the DVD to a digital signal and applies 8 to
15 16 demodulation to the digital signal. It then stores
one error correcting code (ECC) block's worth of the
digital signal obtained by the 8 to 16 demodulation in
a buffer memory, then reads this out, corrects its
errors, and decodes the error corrected digital
20 signal.

Here, the error correction is performed in
units of ECC blocks on the digital signal read from
the DVD.

Figure 1 is a view for explaining the format
25 of an ECC block.

BM,N ($0 \leq M \leq 192$, $0 \leq N \leq 171$) shown in Fig. 1 is information data composed of 16 sectors each comprised by 172 bytes times 12 rows.

BM,N ($0 \leq M \leq 207$, $172 \leq N \leq 181$) is an inner code parity of the Reed-Solomon code.

Namely, the inner code parity BM,N ($172 \leq N \leq 181$) is an inner code parity of the information data BM,N ($0 \leq N \leq 171$).

Also, BM,N ($192 \leq M \leq 207$, $0 \leq N \leq 171$) is an outer code parity of the Reed-Solomon code.

Namely, the outer code parity BM,N ($192 \leq M \leq 207$) is an outer code parity of the information data BM,N ($0 \leq M \leq 192$).

In the above error correction, outer code error correction is performed in units of code blocks corresponding to the columns shown in Fig. 1, while inner code error correction is performed in units of code blocks corresponding to the rows shown in Fig. 1.

In this case, in error correction performed in units of code blocks, the number of bytes able to be corrected for error is determined in accordance with the number of bytes of the parity.

Accordingly, when the playback condition of a DVD is poor and more than a predetermined number of bytes include error, there is a disadvantage that

there are bytes unable to be corrected for error and therefore quality of a digital signal reproduced deteriorates.

Also when recording a digital signal in a DVD, if the recording condition is poor, there is a disadvantage that the quality of the digital signal recorded on the DVD deteriorates.

SUMMARY OF THE INVENTION

An object of the present invention is to provide a readout controlling apparatus capable of reading data from recording media with a good quality and a method of the same.

Another object of the present invention is to provide a player capable of reproducing data from recording media in a good condition.

Still another object of the present invention is to provide a recorder capable of recording data to a recording media well.

To achieve the first object, according to a first aspect of the present invention, there is provided a readout controlling apparatus for controlling reading conditions at the time of reading data from a recording medium, comprising an error correcting means for correcting error of the read data; an error rate

calculating means for calculating an error rate of the error correction; and a control means for controlling the reading conditions in order to make the error rate small.

5 That is, in the readout controlling apparatus of the present invention, data read from a recording medium is corrected for error in the error correcting means. Then, the error rate of the error correction is calculated in the error rate calculating means. The
10 reading condition is controlled by the control means so that the error rate becomes small.

 Preferably, the data is coded in units of predetermined code blocks; the error correcting means corrects the error in units of the code blocks; and
15 the error rate calculating means calculates the error rate by using at least one of the number of bytes of data where the error correction was correctly carried out, the number of bytes of data wherein the error correction was not correctly carried out, the number
20 of code blocks wherein the error correction was correctly carried out, and the number of blocks wherein the error correction was not correctly carried out.

 Preferably, the error rate calculating means
25 calculates the error rate by using results of

cumulative addition of at least one of the number of
bytes of data wherein the error correction was
correctly carried out, the number of bytes of data
wherein the error correction was not correctly carried
out, the number of code blocks wherein the error
correction was correctly carried out, and the number
of blocks wherein the error correction was not
correctly carried out for at least one code block.

More preferably, the readout controlling
apparatus further comprises a cumulative code block
number control means for controlling the cumulative
number of the code blocks.

Preferably, the data comprises the information
data arranged in a two dimensional plane of row and
column directions, an inner code parity indicating an
error correction code in the row direction of every
column, an outer code parity indicating an error
correction code in the column direction of every row,
and the information data and the error correcting
means performs inner code error correction using the
inner code parity and outer code error correction
using the outer code parity.

More preferably, the readout controlling
apparatus further comprises at least one first storage
means for storing the results of cumulative addition

of the inner code error corrections and at least one second storage means for storing the results of cumulative addition of the outer code error corrections.

5 Still more preferably, the error rate calculating means reads the results of cumulative addition stored in the first storage means and the second storage means in a predetermined order.

10 Still further preferably, the first storage means and the second storage means are connected in series so that data stored in former stages can be successively output to latter stages; and the error rate calculating means accesses one of the storage means of the first storage means and the second
15 storage means.

20 Preferably, the recording medium is an optical disk; and the control means controls at least one of an amount of light of a laser diode, a frequency of a signal superimposed on a signal applied to a laser
25 diode, an amplitude of the signal superimposed on the signal applied to a laser diode, a gain of a photodiode, filter characteristics, focus conditions, tracking conditions, RF signal characteristics, an inclination of the optical disk, and a speed of the optical disk.

According to a second aspect of the invention, there is a player, comprising a reproducing means for reproducing data from a recording medium; an error correcting means for correcting error of the reproduced data; an error rate calculating means for calculating an error rate of the error correction; and a control means for controlling reproduction conditions of the reproducing means so that the error rate becomes small.

According to a third aspect of the present invention, there is provided a recorder, comprising a recording means for recording data on a recording medium; a reading means for reading the recorded data; an error correcting means for correcting error of the read data; an error rate calculating means for calculating an error rate of the error correction; and a control means for controlling recording conditions of the recording means so that the error rate becomes small.

According to a fourth aspect of the present invention, there is provided a readout controlling method for controlling reading conditions at the time of reading data from a recording medium including the steps of correcting error of the read data; calculating an error rate of the error correction; and

controlling the reading conditions so that the error rate becomes small.

BRIEF DESCRIPTION OF THE DRAWINGS

5 These and other objects and features of the present invention will become clearer from the following description of the preferred embodiments given with reference to the accompanying drawings, in which:

10 Fig. 1 is a view for explaining the format of an ECC block;

 Fig. 2 is a view of the configuration of a DVD player according to a first embodiment of the present invention;

15 Fig. 3 is a view of the configuration of an error corrector shown in Fig. 2;

 Fig. 4 is a flow chart of the processing of an error correction portion shown in Fig. 3;

20 Fig. 5 is a view of the relationship of a bias and an error rate of a parameter error signal;

 Fig. 6 is a flow chart of generation of a parameter instruction signal in a microcomputer shown in Fig. 2;

25 Fig. 7 is a flow chart of a method of generating a parameter instruction signal in the microcomputer

shown in Fig. 2;

Fig. 8 is a view of the configuration of a DVD player according to a second embodiment of the present invention;

5 Fig. 9 is a view of the configuration of an error corrector shown in Fig. 8;

Fig. 10 is a flow chart of the processing for initialization of the microcomputer shown in Fig. 8;

10 Fig. 11 is a flow chart of the processing for generation of a spindle speed changing instruction signal by the microcomputer shown in Fig. 8;

Fig. 12 is a view of the configuration of a DVD player according to a third embodiment of the present invention;

15 Fig. 13 is a flow chart of the processing for initialization of a microcomputer shown in Fig. 12;

Fig. 14 is a flow chart of the processing for generation of a filter characteristic instruction signal by a microcomputer shown in Fig. 12; and

20 Fig. 15 is a view for explaining a modification of an error corrector shown in Fig. 13.

DESCRIPTION OF THE PREFERRED EMBODIMENTS

Below, preferred embodiments will be described
25 with reference to the accompanying drawings.

First Embodiment

Figure 2 is a view of the configuration of a DVD player according to a first embodiment of the present invention.

5 As shown in Fig. 2, the DVD player 1 comprises a reading system 3, a decoding system 4, an output system 5, and a microcomputer 19.

10 The DVD player 1 calculates an error rate at the microcomputer 19 based on error correction results in an error corrector 17 and controls a focus servomechanism in an optical pickup 13 based on the error rate.

[Reading System 3]

15 The reading system 3 comprises a spindle motor 10, a feed motor 11, a servo controller 12, the optical pickup 13, an RF amplifier 14, and a servo filter 40.

 The servo controller 12 controls the spindle motor 10, feed motor 11, and optical pickup 13.

20 For example, the servo controller 12 generates a focus servo signal based on a parameter instruction signal S19a from the microcomputer 19 and a focus error signal S40 from a servo filter 40 and outputs the generated focus servo signal S12a to the optical
25 pickup 13.

Specifically, the servo controller 12 generates a new focus error signal by giving an offset indicated by the parameter instruction signal S19a to the focus error signal S40 and generates the focus servo signal S12a based on the newly generated focus error signal.

The spindle motor 10 drives rotation of a DVD 2 under the control of the servo controller 12.

The servo filter 40 filters a focus error signal 14b from the RF amplifier 14 by predetermined filter characteristics and outputs the filtered focus error signal S40 to the servo controller 12.

Note that for example a digital filter of a digital signal processor (DSP) is used as the servo filter 40.

The feed motor 11 drives movement of the optical pickup 13 in the diameter direction of the DVD 2 under control of the servo controller 12.

The optical pickup 13 emits laser light to the surface of the DVD 2 via an object lens, receives the reflected light, and outputs a read signal in accordance with results of the received light to the RF amplifier 14.

Also, the optical pickup 13 performs focus control on the focus servo signal S12a from the servo controller 12.

The RF amplifier 14 amplifies the read signal from the optical pickup 13 and outputs the same as an RF signal S14a to an AD converter 15.

Further, the RF amplifier 14 outputs a focus error signal S14b generated based on the read signal from the optical pickup 13 to the servo filter 40.

[Decoding System 4]

The decoding system 4 comprises an AD converter 15, an 8 to 16 demodulator 16, an error corrector 17, a buffer memory 18, a stream demultiplexer 20, a sub-picture decoder 21, a Moving Picture Experts Group (MPEG) decoder 22, an audio decoder 23, a reference clock generator 27, and a video mixer 28.

The AD converter 15 converts an analog RF signal S14a to a digital reproduction signal S15 based on a reference clock signal from the reference clock generator 27 and outputs this to the 8 to 16 demodulator 16.

The 8 to 16 demodulator 16 generates a reproduction signal S16 by demodulating an 8-bit pattern included in the reproduction signal S15 to a 16-bit pattern and outputs the same to the error corrector 17.

The buffer memory 18 has a memory capacity for storing at least one error correction code block's,

that is, ECC block's, worth of the reproduction signal S16 from the 8 to 16 demodulator 16 and outputs the stored reproduction signal to the error corrector 17 under control by the microcomputer 19.

5 The stream demultiplexer 20 demultiplexes a sub-picture signal S20a, a video signal S20b, and an audio signal S20c from the reproduction signal S17 and outputs them to the sub-picture decoder 21, the MEG decoder 22, and the audio decoder 23, respectively.

10 The sub-picture decoder 21 decodes the sub-picture signal S20a and outputs the decoded sub-picture signal S21 to the video mixer 28.

15 The MEG decoder 22 decodes the video signal S20b by the MEG system and outputs the decoded video signal S22 to the video mixer 28.

 The audio decoder 23 decodes the audio signal S20c and outputs a decoded audio signal S23 to a DA converter 26.

20 The video mixer 28 mixes the sub-picture signal S21 with the video signal S22 to generate a video signal S28 and outputs the same to a National Television System Committee (NTSC) encoder 24.

25 The error corrector 17 performs inner code error correction and outer code error correction on the reproduction signal read from the buffer memory 18 in

units of ECC blocks shown in Fig. 1 and outputs the corrected reproduction signal S17 to the stream demultiplexer 20. As an error correction code, for example, a Reed-Solomon code is used.

5 The error corrector 17 will be explained in detail below.

Figure 3 is a view of the configuration of the error corrector 17.

As shown in Fig. 3, the error corrector 17
10 comprises an error correction portion 171, counters 1721 to 1726, registers 1731 to 1736, and a reset signal generation circuit 174.

<Error Correction Portion 171>

First, processing of the error correction portion
15 171 will be explained.

Figure 4 is a flow chart of the processing of the error correction portion 171.

Step S1: The error correction portion 171 judges whether or not one ECC block's worth of the
20 reproduction signal S16 shown in Fig. 1 has been written in the buffer memory 18 shown in Fig. 2. When judged it is written, the processing of Step S2 is performed, while when not, the processing of Step S1 is repeated.

25 Step S2: The error correction portion 171 reads

the data B0,0 to B207,181 shown in Fig. 1 from the
buffer memory 18 in units of PI code blocks comprised
by data B0, M to B207, M ($0 \leq M \leq 181$) as units of error
correction using an inner code parity and performs
5 first inner code error correction in units of the PI
code blocks.

Specifically, the data B0,0 to B207,0 is read
from the buffer memory 18 first and then the data B0,1
to B207,1 is read. Then, data is read in units of PI
10 code blocks in the order of the data B0,2 to B207,2,
data B0,3 to B207,3, ..., data B0,181 to B207,181 so
that the inner code error correction is performed.

The error correction portion 171 detects in units
of bytes whether or not the inner code error
15 correction was correctly performed at the time of the
first inner code error correction, generates an error
correction completion byte detection signal S171a1
which generates a pulse every time the fact that the
inner code error correction was correctly performed
20 was detected, and outputs the same to the counter
1721.

Further, the error correction portion 171 detects
a PI code block wherein the inner code error
correction was not correctly performed at the time of
25 performing the first inner code error correction,

generates a PI(1) error correction inability code block detection signal S171a2 every time such a PI code block is detected, and outputs the same to the counter 1722.

5 Step S3: The error correction portion 171 reads the data B0,0 to B207,181 shown in Fig. 1 from the buffer memory 18 in units of PO code blocks comprised by the data BN,0 to BN,181 ($0 \leq N \leq 207$) as units of error correction using an outer code parity and performs
10 outer code error correction in units of PO code blocks.

Specifically, the data B0,0 to B0,181 is read from the buffer memory 18 first, and then data B1,0 to B1,181 is read next. Then, data is read in units of PO
15 code blocks in the order of the data B2,0 to B2,181, data B3,0 to B3,181, ..., data B207,0 to B207,181 so as to perform the outer code error correction.

The error correction portion 171 detects in units of bytes whether or not the outer code error
20 correction was correctly performed at the time of performing the outer code error correction, generates a PO error correction completion byte detection signal S171a3 which generates a pulse every time the fact that the outer code error correction was correctly
25 performed was detected, and outputs the same to the

counter 1723.

Further, the error correction portion 171 detects a PO code block wherein the outer code error correction was not correctly performed at the time of performing the outer code error correction, generates a PO error correction inability code block detection signal S171a4 every time the PO code block is detected, and outputs the same to the counter 1724.

Step S4: The error correction portion 171 reads the data B0,0 to B207,181 shown in Fig. 1 from the buffer memory 18 in units of PI code blocks comprised by data B0,M to B207,M($0 \leq M \leq 181$) as units of error correction using an inner code parity and performs second inner code error correction in units of PI code blocks.

Specifically, the data B0,0 to B207,0 is read from the buffer memory 18 first and then the data B0,1 to B207,1 is read. Then, data is read in units of PI code blocks in the order of the data B0,2 to B207,2, data B0,3 to B207,3, ..., data B0,181 to B207,181 so that the second inner code error correction is performed.

The error correction portion 171 detects in units of bytes whether or not the inner code error correction was correctly performed at the time of the

second inner code error correction, generates a PI(2)
error correction completion byte detection signal
S171a5 which generates a pulse every time the fact
that the inner code error correction was correctly
5 performed was detected, and outputs the same to the
counter 1725.

Further, the error correction portion 171 detects
a PI code block wherein the inner code error
correction was not correctly performed at the time of
10 performing the second inner code error correction,
generates a PI(2) error correction inability code
block detection signal S171a6 every time the PI code
block is detected, and outputs the same to the counter
1726.

15 Step S5: The error correction portion 171
generates a pulse in an ECC block correction
completion signal S171b output to the reset signal
generation circuit 174.

<Counters 1721 to 1726>

20 The counter 1721 counts the pulses included in
the PI(1) error correction completion byte detection
signal S171a1 and outputs the count to the register
1731 as a PI(1) error correction completed byte number
instruction signal S1721.

25 The counter 1722 counts the pulses included in

the PI(1) error correction inability code block detection signal S171a2 and outputs the count to the register 1732 as a PI(1) error correction inability code block number instruction signal S1722.

5 The counter 1723 counts the pulses included in the PO error correction completion byte detection signal S171a3 and outputs the count to the register 1733 as a PO error correction completion byte number instruction signal S1723.

10 The counter 1724 counts the pulses included in the PO error correction inability code block detection signal S171a4 and outputs the count to the register 1734 as a PO error correction inability code block number instruction signal S1724.

15 The counter 1725 counts the pulses included in the PI(2) error correction completion byte detection signal S171a5 and outputs the count to the register 1735 as a PI(2) error correction completion byte number instruction signal S1725.

20 The counter 1726 counts the pulses included in the PI(2) error correction inability code block detection signal S171a6 and outputs the count to the register 1736 as a PI(2) error correction inability code block number instruction signal S1726.

25 Here, the counters 1721 to 1726 reset their

counts to zero when a pulse is generated in a reset signal S174.

<Reset Signal Generation Circuit 174>

5 The reset signal generation circuit 174 counts the pulses including in the ECC block correction completion signal S171b and, when the count has reached a predetermined value, generates a pulse in the reset signal S174 to reset the count. The reset
10 signal generation circuit 174 outputs the reset signal S174 to the counters 1721 to 1726, the registers 1731 to 1736, and microcomputer 19.

Note that the predetermined value shows the number of ECC blocks cumulatively added by the counters 1721 to 1726 and is set by a setting signal
15 S19b from the microcomputer 19. In this embodiment, it is for example "1".

<Registers 1731 to 1736>

The registers 1731 to 1736 are connected in series so that the stored data in the final register
20 1731 is output to the microcomputer 19. At this time, the data output from the register 1731 to the microcomputer 19 becomes an error correction evaluation signal S17a.

The registers 1731 to 1736 output the stored data
25 to the succeeding registers and store data input from

the preceding registers every time a pulse is generated in the reset signal S174.

The register 1731 stores the PI(1) error correction completion byte number instruction signal S1721 input from the counter 1721.

The register 1732 stores the PI(1) error correction inability code block number instruction signal S1722 input from the counter 1722.

The register 1733 stores the PO error correction completion byte number instruction signal S1723 input from the counter 1723.

The register 1734 stores the PO error correction inability code block number instruction signal S1724 input from the counter 1724.

The register 1735 stores the PI(2) error correction completion byte number instruction signal S1725 input from the counter 1725.

The register 1735 stores the PI(2) error correction inability code block number instruction signal S1725 input from the counter 1725.

<Output System 5>

The output system 5 comprises an NTSC encoder 24, a DA converters 25 and 26, and speakers 31.

The NTSC encoder 24 decodes the video signal S28 by the NTSC system and outputs a decoded video signal

S24 to the DA converter 25.

The DA converter 25 converts the video signal S24 to an analog video signal S25 and outputs the same to a display 30.

5 The DA converter 26 converts the digital audio signal S23 to an analog audio signal S26 and outputs the same to speakers 31.

<Microcomputer 19>

10 The microcomputer 19 generates an error rate by using the error correction evaluation signal S17a from the error corrector 17, determines a bias of a focus error signal in order to suppress defocus based on the generated error rate, and generates a parameter
15 instruction signal indicating the bias.

Below, a method of calculation of the error rate in the microcomputer 19 will be explained.

Here, when the PI(1) error correction completion byte number instruction signal S1721, the PI(1) error
20 correction inability code block number instruction signal S1722, the PO error correction completion byte number instruction signal S1723, the PO error correction inability code block number instruction signal S1724, the PI(2) error correction completion
25 byte number instruction signal S1725, and the PI(2)

error correction inability coding number instruction signal S1725 are respectively a, b, c, d, e, and f, the error rate ER is represented, for example, by the equation (1) below.

5
$$ER = \{(a+c+e)/(\text{number of bytes included in 1 EEC block} \times 3) \times 1/5 + \{d/(\text{number of PO code blocks}) + (b+f)/(\text{number of PI code blocks} \times 2)\} \times 4/5 \dots (1)$$

10 Namely, in equation (1), the error rate ER is calculated by using both of the number of bytes for which error correction was completed and the number of code blocks for which error correction was not possible in one outer code error correction and two inner code error corrections and larger weight is
15 given to the number of code blocks for which error correction was not possible compared with the number of bytes for which error correction was completed.

20 A method of generating a parameter instruction signal S19a in the microcomputer 19 will be explained below.

 The parameter instruction signal indicates the bias to be given to the focus error signal as explained above. The bias is generated by using the parameter error signal.

25 Here, the parameter error signal is the

difference from an optimal value of the bias.

Note that the optimal value of the bias is, as shown in Fig. 5, a bias value by which the error rate becomes the smallest.

5 First, a method of generating the parameter error signal in the microcomputer 19 will be explained.

Figure 6 is a flow chart for generation of the parameter error signal in the microcomputer 19.

10 A parameter "prt" is determined by adding or subtracting an amplitude value "amp" to or from a central value "cent". The time from changing the parameter until fetching the error rate shown as "period". Further, the cumulative value of the parameter error signal is shown as "mes". The number
15 of cumulative additions of the parameter signal is shown as "cnt".

Step S101: The microcomputer 19 sets the cumulative value "mes" of the parameter signal to an initial value of 0.

20 Step S102: The microcomputer 19 judges whether the number of cumulative additions "cnt" is 0 or not. When it is 0, it ends the processing, while when it is not, carries out the processing of Step S103.

Step S103: The microcomputer 19 adds an amplitude
25 value "amp" to a central value "cent" and assigns the

added result to the parameter "prt".

Step S104: The microcomputer 19 waits for exactly a time of "period"/2.

5 Step S105: The microcomputer 19 uses the error correction evaluation signal S17a input from the register 1731 shown in Fig. 3 to calculate the error rate ER based on the above equation (1) and inserts the error rate ER for the variable "mes2".

10 Step S106: The microcomputer 19 subtracts the amplitude value "amp" from the central value "cent" and inserts the subtracted result for the parameter "prt".

Step S107: The microcomputer 19 waits for exactly a time of "period"/2.

15 Step S108: The microcomputer 19 uses the error correction evaluation signal S18a input from the register 1731 shown in Fig. 3 to calculate the error rate ER based on the above equation (1), subtracts the error rate ER from the variable "mes2", and inserts
20 the subtracted result for the variable "mes2".

At this time, the value indicated by the variable "mes2" is the value of a parameter signal cumulatively added once.

25 Step S109: The microcomputer 19 judges whether or not the variable "mes2" obtained at step S108 is

larger than a predetermined value "PRT_ERRTH". When judged to be larger, it returns to the processing of Step S102, while when judged smaller, it carries out the processing of Step S110.

5 Here, the variable "mes2" becomes under the predetermined value "PRT_ERRTH" under normal measurement conditions, however, when there are scratches, dirt, etc. on the surface of the DVD 2, it becomes over the predetermined value "PRT_ERRTH" in
10 some cases. Therefore, a variable "mes2" not less than the predetermined value "PRT_ERRTH" is judged to be incorrect data, and the value of the variable "mes2" is not added to the cumulative value "mes" of the parameter error signal. That is, it is discarded.

15 Step S110: The microcomputer 19 adds the value of the variable "mes2" obtained at Step S108 to the cumulative value "mes" of the parameter signal and makes the added result the cumulative value "mes".

20 Step S111: The microcomputer 19 decreases the number of cumulative additions "cnt" of the parameter signal by exactly 1.

25 Namely, in the processing shown in Fig. 6, when the variable "mes2", which shows the error rate in a case where the parameter "prt" is "cent+amp" minus the error rate ER in a case where the parameter "prt" is

"cent-amp", is less than the predetermined value
"PRT_ERRTH", the variable "mes2" is added to the
cumulative value "mes" of the parameter error signal
(namely, the variable "mes2" is used for cumulative
5 addition), and the cumulative value "mes" after
addition the number of times shown in "cnt" is made
the finally obtained parameter error signal.

Here, the processing loop from the above Step
S102 to Step S111 means to multiply and extract a
10 square wave.

For example, suppose there is a sample data row
of "d1, d2, d3, d4, ...". If a square wave is
multiplied with this, it becomes "d1, -d2, d3, -d4,
..." Further, when it is cumulatively added, the
15 cumulative value "sum" becomes as in equation (2)
below.

$$sum = \sum_{i=2}^n (d(i-1) - di) \quad \dots(2)$$

Here, "sum" in equation (2) corresponds to the
cumulative value "mes" in Fig. 6, and (d(i-1)-di)
20 corresponds to the variable "mes2" in Fig. 6.

A method of cumulative addition by multiplying
with a square wave was explained above, however, a
sinusoidal wave etc. may be multiplied for cumulative

addition as well.

Next, a method of generating a parameter instruction signal by feeding back the parameter error signal generated by the processing shown in Fig. 6 in the microcomputer 19 will be explained next.

Figure 7 is a flow chart of a method of generating a parameter instruction signal in the microcomputer 19.

Step S201

The microcomputer 19 performs the initialization. Specifically, a central value "cent" of the parameter is set to 0, an amplitude value "amp" is set to "PRT_AMP", "period" is set to two times "PRT_PER" of a 1/2 modulation cycle, and "cnt" is set to "PRT_CNT".

Step S202

The microcomputer 19 performs processing based on Fig. 6 and generates a parameter error signal "mes".

Step S203

The microcomputer 19 compares an absolute value of the parameter error signal "mes" obtained at Step S202 with an automatic adjustment completion condition, that is, a threshold value "PRT_E". When it is smaller than "PRT_E", it performs the processing of Step S204, while when not, it performs processing of Step S205.

Step S204

The microcomputer 19 completes the processing by setting the central value "cent" of the parameter used at Step S202 as a parameter "prt".

5 Step S205

The microcomputer 19 multiplies a predetermined gain "PRT_G" with the parameter error signal obtained at Step S202, adds the result to the central value "cent" of the parameter, substitutes the added result to the central value "cent", and returns to the processing of Step S202.

10 Next, the microcomputer 19 continues measuring by changing the central value "cent" of the parameter until the parameter error signal "mes" becomes less than the threshold value "PRT_E" at Step S203.

15 Note that the gain "PRT_G" may be subtracted at Step S205 as well. By doing so, it is possible to gradually decrease the gain to prevent the processing from being disturbed by noise.

20 Note that the above parameter may be generated before and while playing back the DVD 2. Also, it may be generated when the playback condition deteriorates.

 Next, the overall operation of the DVD player 1 will be explained with reference to Fig. 2.

25 First, the DVD 2 is rotated driven by the spindle

motor 10 under the control of the servo controller 12.
A signal read from the DVD 2 by the optical pickup 13
is then output to the RF amplifier 14. The read signal
is amplified by the RF amplifier 14 and output to the
5 AD converter 15 as an RF signal S14a.

The RF signal S14a is converted to a digital
reproduction signal S15 in the AD converter 15 and
output as a reproduction signal S15 to the 8 to 16
demodulator 16.

10 The reproduction signal S15 is subjected to 8 to
16 demodulation in the 8 to 16 demodulator 16.

Then, the demodulated reproduction signal S16 is,
as explained above, stored in the buffer memory 18,
then corrected for error in units of ECC blocks in the
15 error correction portion 171 of the error corrector 17
shown in Fig. 3 to generate a reproduction signal S17.

Also, in the error correction portion 171, as
explained above, the PI(1) error correction completion
byte detection signal S171a1, PI(1) error correction
20 inability code block detection signal S171a2, PO error
correction completion byte detection signal S171a3, PO
error correction inability code block detection signal
S171a4, PI(2) error correction completion byte
detection signal S171a5, and PI(2) error correction
25 inability code block detection signal S171a6 are

generated.

Next, the pulses included in the detection signals S171a1 to 171a6 are counted in the counters 1721 to 1726. The counts are stored in the registers 1731 to 1736 and then output as the error correction evaluation signal S17a to the microcomputer 19.

Next, an error rate is calculated by using the error correction evaluation signal S17a in the microcomputer 19, a bias of a focus error signal is determined in order to suppress defocusing based on the calculated error rate, and a parameter instruction signal S19a indicating the bias is output to the servo controller 12.

In the servo controller 12, a focus servo signal is generated based on the parameter instruction signal S19a from the microcomputer 19 and a focus error signal S40 from the servo filter 40, and the generated focus servo signal S12a is output to the optical pickup 13.

As a result, focus control is performed to suppress defocusing in the optical pickup 13.

On the other hand, an error corrected reproduction signal S17 output from the error corrector 17 to the stream demultiplexer 20 is demultiplexed to a sub-picture signal S20a, a video

signal S20b, and an audio signal S20c which are output respectively to the sub-picture decoder 21, MEG decoder 22, and audio decoder 23.

5 Next, the sub-picture signal S20a is decoded in the sub-picture decoder 21, and the decoded sub-picture signal S21 is output to the video mixer 28.

The video signal S20b is decoded in the MEG decoder 22, and the decoded video signal S22 is output to the video mixer 28.

10 The audio signal S20c is decoded in the audio decoder 23, and the decoded audio signal S23 is output to the DA converter 26.

15 The sub-picture signal S20a is mixed in the video mixer with the video signal S22, and the resultant mixed video signal S28 is output to the NTSC encoder 24.

Then, the video signal S28 is decoded by the NTSC system in the NTSC encoder 24, and the decoded video signal S24 is output to the DA converter 25.

20 The video signal S24 is converted to an analog video signal S25 by the DA converter 25, and the video signal S25 is output to the display 30.

Also, the audio signal S23 is converted to an analog audio signal S26 in the DA converter 26, and
25 the audio signal S26 is output to the speakers 31.

As explained above, according to the DVD player 1, a focus servo signal S12a is generated and the optical pickup 13 is controlled in order to suppress defocusing based on the error rate obtained at the time of the error correction of the reproduction signal of the DVD 2.

Therefore, even when the state of focus on the DVD 2 in the optical pickup 13 is poor, the DVD 2 can be accurately and stably played back due to the improvements.

Further, according to the DVD player 1, since the error correction evaluation signal S17a is generated in the error corrector 17, the load on the microcomputer 19 can be reduced.

Also, according to the DVD player 1, as shown in Fig. 3, by limiting the registers which the microcomputer 19 accesses to the register 1731 among the registers 1731 to 1736 in the error corrector 17, the overhead of register access by the microcomputer 19 can be reduced.

Second Embodiment

Figure 8 is a view of the configuration of a DVD player 201 according to a second embodiment of the present invention.

In Fig. 8, components having the same reference

numerals as in Fig. 2 are the same as those explained in the first embodiment.

Namely, the DVD player 201 is characterized by its servo controller 212, error corrector 217, and microcomputer 219.

[Servo Controller 212]

The servo controller 211 controls the spindle motor 10, feed motor 11, and optical pickup 13.

In the present embodiment, the servo controller 211 controls the speed of the spindle motor 10 based on a spindle speed change instruction signal S219a from the microcomputer 19.

[Error Corrector 217]

Figure 9 is a view of the configuration of the error corrector 217.

In Fig. 9, components having the same reference numerals as in Fig. 3 are the same as in the error corrector 17 explained in the first embodiment.

As shown in Fig. 9, the error corrector 217 comprises an error correction portion 171, counters 1721 to 1726, registers 1731 to 1736, a reset signal generation circuit 274, and a cumulative block number control circuit 275.

Here, in the error corrector 217, the error correction portion 171, the counters 1721 to 1726, and

the registers 1731 to 1736 are the same as those explained in the first embodiment.

5 The cumulative block number control circuit 275 changes the cumulative number of blocks set in the reset signal generation circuit 274 in accordance with a cumulative block number change signal S219b from the microcomputer 219.

10 The reset signal generation circuit 274 counts the pulses included in the ECC block correction completion signal S171b and, when the count reaches the cumulative number of blocks, generates a pulse in the reset signal S274 to reset the count. The reset signal generation circuit 274 outputs the reset signal S274 to the counters 1721 to 1726, registers 1731 to 15 1736, and the microcomputer 219.

Also, the reset signal generation circuit 274 changes the cumulative number of blocks under the control of the cumulative block number control circuit 275.

20 [Microcomputer 219]

 The microcomputer 219 uses an error correction evaluation signal S17a from the error corrector 217 to calculate the error rate and generates a spindle speed change instruction signal S219a for instructing a change of the speed of the spindle motor 10 based on 25

the calculated error rate.

Figure 10 is a flow chart of the processing for initialization of the microcomputer 219.

Step S301: The microcomputer 219 sets an initial
5 value for the cumulative number of blocks.

Step S302: The microcomputer 219 sets an initial
value for the target error rate "ER_PI1_THR".

Figure 11 is a flow chart of the processing for
generation of a spindle speed change instruction
10 signal S219a by the microcomputer 219.

The processing shown in Fig. 11 is carried out
after completing the initialization shown in Fig. 10.

Step S401

The microcomputer 219 judges whether or not the
15 cumulative addition in the error corrector 217 is
completed, for example, based on the reset signal S274
from the reset signal generation circuit 274. When it
is judged to be completed, it carries out the
processing of Step S402, while when not, it repeats
20 the processing of Step S401.

At this time, processing is performed for
cumulative addition of the number of bytes for which
error correction is completed and number of code
blocks for which error correction was not possible for
25 the cumulative number of blocks's worth of ECC blocks

set by the reset signal generation circuit 274 in the error corrector 217.

Step S402

5 The microcomputer 219 receives as input a PI(1) error correction completion byte number instruction signal S1721 as an error correction evaluation signal S17a.

Step S403

10 The microcomputer 219 judges whether the PI(1) number of bytes for which error correction was completed indicated by the PI(1) error correction completion byte number instruction signal S1721 input at Step S402 is 0 or not. When judged to be 0, it performs the processing of Step S404, while when not, 15 it carries out the processing of Step S406.

Step S404

20 The microcomputer 219 outputs a cumulative block number change signal S219b indicating to increase the cumulative number of blocks to the cumulative block number control circuit 275.

The cumulative block number control circuit 275 increases the cumulative number of blocks set in the reset signal generation circuit 274 by exactly a predetermined number based on the cumulative block 25 number change signal S219b.

Step S405

The microcomputer 219 updates the target error rate "ERR_PI1_THR" by a value according to the cumulative number of blocks increased at Step S404.

5 Step S406

10 The microcomputer 219 judges whether or not the PI(1) number of bytes for which error correction was completed indicated by the PI(1) error correction completion byte number instruction signal S1721 input at Step S402 is more than the target error rate "ERR_PI1_THR". When judged to be more than the target error rate "ERR_PI1_THR", it performs the processing of Step S407, while when judged to be smaller, it carries out the processing of Step S408.

15 Step S407

The microcomputer 219 outputs a spindle speed change instruction signal S219a for instructing a decrease of the speed of the spindle motor 10 to the servo controller 212.

20 As a result, the speed of the spindle motor decreases.

Step S408

25 The microcomputer 219 outputs a spindle speed change instruction signal S219a to instruct an increase of the speed of the spindle motor 10 to the

servo controller 212.

As a result, the speed of the spindle motor 10 increases.

As explained above, according to the DVD player
5 201, the speed of the spindle motor 10 is controlled based on the error rate obtained at the time of the error correction of the reproduction signal of the DVD 2.

Namely, in the DVD player 201, by decreasing the
10 speed of the spindle motor 10 when the error rate is more than the target error rate, the playback conditions are improved. In this case, when the speed of the spindle motor 10 is decreased, the transfer rate becomes lower, however, retries of the read
15 operation due to a failure of reading data from the DVD 2 can be eliminated and the read time can be shortened.

Further, in the DVD player 201, by increasing the
20 speed of the spindle motor when the error rate is smaller than the target error rate, the transfer rate can be made higher within a range able to obtain the target error rate.

Note that in the DVD player 201, a case was
25 explained where the spindle speed change instruction signal S219a is generated by using only the PI(1)

error correction completion byte number instruction
signal S1721, however, it is also possible to use the
instruction signals S1722 to S1726 by increasing the
number of pulses generated in the reset signal S174.

5 In this case, by storing the instruction signals
S1721 to S1726 in the order of importance from the
registers 1731 to 1736, instruction signals of higher
importance can be supplied at a higher priority
compared with the instructions of a lower importance
10 to the microcomputer 219 in accordance with the number
of pulses included in the reset signal S274 from the
reset signal generation circuit 274.

 Note that the importances of the instruction
signals S1721 to S1726 are determined, for example,
15 based on the playback conditions.

 Specifically, when the error rate is less than a
predetermined value (when the playback conditions are
good), since every count except for the PI(1) number
of bytes for which error correction was completed
20 becomes zero, the PI(1) error correction completion
byte number instruction signal S1721 is made the most
important. When the error rate exceeds the
predetermined value (when the playback conditions are
poor), the PO error correction completion byte number
25 instruction signal S1723 is made the most important.

Further, other than determining the cumulative block number change signal S219b based on the instruction signals S1721 to S1726, the microcomputer 219 may determine the cumulative block number change signal S219b so as to decrease the cumulative number of blocks when the instantaneous error rate is important and so as to increase the cumulative number of blocks when an error rate average for a certain period is important.

Third Embodiment

Figure 12 is a view of the configuration of a DVD player 301 according to a third embodiment of the present invention.

In Fig. 12, components having the same reference numerals as in Fig. 2 and Fig. 8 are the same as those in the first and second embodiments.

Namely, the DVD player 301 is characterized in its servo filter 340 and microcomputer 319.

[Servo Filter 340]

The servo filter 340 filters the focus error signal S14b from the RF amplifier 14 by predetermined filter characteristics and outputs the filtered focus error signal S34c to the servo controller 12.

Note that, for example, a digital filter of a DSP is used as the servo filter 340. One set of filter

characteristics is selected from filter
characteristics for scratched disks and filter
characteristics for scratch-free disks in accordance
with a filter characteristic instruction signal S319a
5 from the microcomputer 319 to filter the focus error
signal, tracking error signal, etc. from the RF
amplifier 14.

[Microcomputer 319]

The microcomputer 319 generates an error rate by
10 using an error correction evaluation signal S17a from
the error corrector 217 shown in Fig. 9 and generates
a filter characteristic instruction signal S319a to
instruct the filter characteristics of the servo
filter 340 based on the generated error rate.

15 Figure 13 is a flow chart of the processing for
initialization of the microcomputer 319.

Step S501

The microcomputer 319 sets an initial value for
the cumulative number of blocks.

20 Step S502

The microcomputer 319 sets an initial value for
the error rate "ER_PI1_IMP_THR".

Step S503

The microcomputer 319 sets an initial value
25 "CNT_ND_MAX" for a scratch-free disk hysteresis

"CNT_ND".

Step S504

The microcomputer 319 sets an initial value
"CNT_D_MAX" for a scratched disk hysteresis "CNT_D".

5 Step S505

The microcomputer 319 outputs the filter
characteristic instruction signal S319a to instruct
selection of the filter characteristics for scratch-
free disks to the servo filter 340.

10 As a result, the servo filter 340 filters the
focus error signal S14b etc. from the RF amplifier 14
by the filter characteristics for scratch-free disks.

Figure 14 is a flow chart of the processing for
generation of the filter characteristic instruction
signal S319a by the microcomputer 319.

15 The processing shown in Fig. 14 is performed
after completing the initialization shown in Fig. 13.

Step S601

20 The microcomputer 319 judges whether or not
cumulative addition is completed in the error
corrector 217 based on, for example, a reset signal
S274 from the reset signal generation circuit 274.
When it is judged to be completed, it carries out the
processing of Step S602, while when not, it repeats
25 the processing of Step S601.

At this time, in the error corrector 217,
cumulative addition of the number of bytes for which
error correction was completed and the number of code
blocks for which error correction was not possible is
5 performed for the cumulative number of blocks' worth
of ECC blocks set in the reset signal generation
circuit 274.

Step S602

10 The microcomputer 319 receives as input the PI(1)
error correction completion byte number instruction
signal S1721 as an error correction evaluation signal
S17a.

Step S603

15 The microcomputer 319 judges whether the PI(1)
number of bytes for which error correction has been
completed indicated by the PI(1) error correction
completion byte number instruction signal S1721 input
at Step S602 is 0 or not. When it is judged to be 0,
it carries out the processing of Step S604, while when
20 not, it performs the processing of Step S606.

Step S604

25 The microcomputer 319 outputs a cumulative block
number change signal S319b indicating to increase the
cumulative number of blocks to the cumulative block
number control circuit 275 of the error corrector 217.

The cumulative block number control circuit 275 increases the cumulative number of blocks set in the reset signal generation circuit 274 by exactly a predetermined number based on the cumulative block number change signal S319b.

Step S605

The microcomputer 319 updates the target error rate "ERR_PI1_IMP_THR" by a value according to the cumulative number of blocks increased at Step S604.

Step S606

The microcomputer 319 judges whether or not the PI(1) number of bytes for which error correction was completed indicated by the PI(1) error correction completion byte number instruction signal S1721 input at Step S602 is more than the target error rate "ERR_PI1_IMP_THR". When judged to be more than the aimed error rate "ERR_PI1_IMP_THR", it performs the processing of Step S609, when when judged to be less than the target error rate "ERR_PI1_IMP_THR", it carries out the processing of Step S607.

Step S607

The microcomputer 319 subtracts exactly 1 from the value of the scratch-free disk hysteresis "CNT_ND".

Step S608

The microcomputer 319 sets an initial value
"CNT_D_MAX" for the scratched disk hysteresis "CNT_D".

Step S609

5 The microcomputer 319 subtracts exactly 1 from
the value of the scratched disk hysteresis "CNT_D".

Step S610

The microcomputer 319 sets an initial value
"CNT_ND_MAX" for the scratch-free disk hysteresis
"CNT_ND".

10 Step S611

The microcomputer 319 judges whether the
scratched disk hysteresis "CNT_D" is 0 or not. When
judged to be 0, it performs the processing of Step
S612, when not, it performs the processing of Step
15 S613.

Here, it is judged that the scratched disk
hysteresis "CNT_D" is 0 when it is successively judged
exactly for the times indicated by the initial value
"CNT_D_MAX" that the PI(1) number of bytes for which
20 error correction has been completed is more than the
target error rate "ERR_PI1_IMP_THR".

Step S612

The microcomputer 319 outputs a filter
characteristic instruction signal S319a indicating
25 selection of the filter characteristics for scratched

disks to the servo filter 340.

As a result, the focus error signal S14b etc. from the RF amplifier 14 are filtered with the filter characteristics for scratched disks.

5 Step S613

The microcomputer 319 judges whether or not the scratch-free disk hysteresis "CNT_ND" is 0 or not. When judged to be 0, it performs the processing of Step S614, when not, it returns to the processing of Step S601.

Here, the scratch-free disk hysteresis CNT_D is judged to be 0 when it is successively judged exactly for the times indicated by the initial value "CNT_ND_MAX" that the PI(1) number of bytes for which error correction has been completed is smaller than the target error rate "ERR_PI1_IMP_THR" at Step S606.

15 Step S614

The microcomputer 319 outputs a filter characteristic instruction signal S319a indicating selection of the filter characteristics for scratch-free disks to the servo filter 340.

As a result, the focus error signal S14b etc. from the RF amplifier 14 are filtered with the filter characteristics for scratch-free disks.

25 As explained above, according to the DVD player

301, the filter characteristics of the servo filter 340 are controlled based on the error rate obtained at the time of performing error correction on the reproduction signal of the DVD 2.

5 Namely, in the DVD player 301, in the servo filter 340, the focus error signal etc. are filtered with the filter characteristics for scratched disks when the error rate is more than the target error rate, while the focus error signal etc. are filtered
10 with the filter characteristics for scratch-free disks when the error rate is smaller than the target error rate.

 Accordingly, a highly accurate focus error signal S34c etc. can be generated and the servo performance
15 of the servo controller 12 can be improved.

 Note that in the DVD player 301, a case was explained where the filter characteristic instruction signal S319a is generated by using only the PI(1) error correction completion byte number instruction
20 signal S1721, however, instruction signals S1722 to 1726 may be used by increasing the number of pulse generated in the reset signal S174.

 The present invention is not limited to the above embodiments.

25 For example, in the above embodiments, a case was

explained of reproducing a digital signal recorded on
a DVD 2 by a DVD player, however, the present
invention can be applied to a case of recording a
digital signal on a DVD 2 as well. In this case, a
5 recording means is further added to the configuration
shown in Fig. 2. After recording a digital signal on
the DVD 2 by the recording means, the recorded digital
signal is read from the DVD 2 in the same way as in
the above first embodiment to obtain an error rate and
10 the recording conditions of the recording means are
controlled so that the error rate becomes smaller.

For example, in the above embodiments, as shown
in Fig. 3, a case was explained where the instruction
signals S1721 to S1726 from the counters 1721 to 1726
15 are output respectively to the registers 1731 to 1736,
however, as shown in Fig. 15, by providing a selector
180 between the counters 1721 to 1726 and the
registers 1731 to 1736, the instruction signals S1721
to S1726 may be output from the counters 1721 to 1726
20 to any registers 1731 to 1736 in accordance with a
switching signal S19c from the microcomputer 19.

As a result, the PI(1) error correction
completion byte detection signal S171a1, the PI(1)
error correction inability code block detection signal
25 S171a2, the PO error correction completion byte

detection signal S171a3, the PO error correction inability code block detection signal S171a4, the PI(2) error correction completion byte detection signal S171a5, and the PI(2) error correction inability code block detection signal S171a6 can be output in any order as an error correction evaluation signal S17a to the microcomputer 19.

As a result, in the microcomputer 19, it becomes possible to generate an error rate by using any set of instruction signals among the instruction signals S1721 to S1726.

Also, in the above embodiments, a case was explained where PI(1) error correction, PO error correction, and PI(2) error correction are successively performed, however, the present invention can be applied to a variety of cases performing one or more of the PI error correction and PO error correction, such as successively performing PI error correction and PO error correction, performing only PI error correction, and performing only PO error correction.

Also, in the above embodiments, a case was explained of obtaining an error rate by using the above formula (1), however, the method of calculation of the error rate is not specifically limited as long

as using at least one of the number of bytes of data wherein the error correction was correctly performed, the number of bytes of data wherein the error correction was not correctly performed, the number of code blocks wherein the error correction was correctly performed, and the number of blocks wherein the error correction was not correctly performed.

For example, by using a, b, c, d, e, and f used in equation (1), an error rate ER1 according to a and b, an error rate ER2 according to c and d, and an error rate ER3 according to e and f may be separately calculated. In this case, the playback conditions are controlled in accordance with a predetermined rule based on the error rates ER1, ER2, and ER3.

Also, in the above embodiments, a DVD was explained as a recording medium, however, the present invention can be applied to cases of playing back a compact disk, opto-magnetic disk, etc.

Also, the object to be controlled by the microcomputer based on the error rate is not specifically limited as far as it is a parameter regarding reading, playback, and recording of a recording medium.

For example, the present invention may control the amount of light generated by a laser diode, the

frequency of the signal superimposed on the signal applied to the laser diode, an amplitude of the signal superimposed on the signal applied to the laser diode, the gain of the photodiode, tracking condition, RF
5 signal characteristics, inclination of the optical disk, and speed of the optical disk so that the error rate becomes smaller.

As explained above, according to the readout controlling apparatus and method of the present
10 invention, data can be read from a recording medium stably and accurately (at a high quality).

Also, according to the player of the present invention, a recording medium can be played back stably and accurately.

15 Further, according to the recorder of the present invention, a recording medium can be recorded on stably and accurately.

While the invention has been described with reference to specific embodiment chosen for purpose of
20 illustration, it should be apparent that numerous modifications could be made thereto by those skilled in the art without departing from the basic concept and scope of the invention.